//pushPneumatics();

StartTask(CollectD);

{

drive\_straight(127,12);

wait1Msec(1000);

stopCollectors();

StopTask(CollectD);

}

lift(medgoal);

spit(2);

//TurnGyro(right,50,90,2);

/\*drive\_straight(127,12);

medgoal(3);

drive\_straight(127,8);

medgoal(3);//maintain arm pos.\*/